

Power d Tool

Background of the Invention

1. Field of the Invention

5 **[0001]** The present invention relates to a tool for a powered machine, the tool having vibration damping means.

2. Description of the Related Art

10 **[0002]** A type of powered machine has a driver arranged to operatively drive a tool. An example of such a powered machine is a pavement breaker. Typically, a tool inserts into the driver and the driver drives the tool in a percussive and/or rotary manner; the tool functioning to transfer the energy imparted thereto from the driver to the medium against which the tool is worked.

15 **[0003]** Associated with powered machines are noise and vibration. Such effects are undesirable, especially for operators of powered machines, and present health risks. For example, high levels of noise can cause noise-induced hearing loss. Practical measures that can be taken to reduce the effects of noise on an operator are to provide the operator with ear defenders and to provide the operator with a driver fitted with silencing means.

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25 **[0004]** Powered machine operators are particularly at risk from hand-arm-vibration syndrome; a condition that can affect circulation, sensory and motor nerves and can cause musculo-skeletal problems. Practical measures to reduce the effects of vibration on an operator from existing powered

machines are to ensure that each powered machine is worked in accordance with manufacturer instructions.

5 **[0005]** Although means to protect an operator of a powered machine from potentially injurious noise and vibrations therefrom are useful, it is desirable in powered machine technology to reduce such vibration and noise emanating from the powered machine in the first place.

Brief Summary of the Invention

10 **[0006]** According to a first aspect of the present invention there is provided a method for providing a tool for a powered machine, the tool having vibration damping means, said method comprising the steps of: a) determining an estimated antinode position of vibration of the tool in use when the tip of the shaped working end is hinged and the tip of the striking
15 end is free to vibrate; and b) locating a vibration damping member to cover the antinode position determined in step a).

20 **[0007]** According to a second aspect of the present invention there is provided a tool for a powered machine, the tool having vibration damping means, said vibration damping means comprising a vibration damping member located to cover an estimated antinode position of vibration of the tool in use when the tip of the shaped working end is hinged and the tip of the striking end is free to vibrate.

Brief Description of the Several Views of the Drawings

[0008] *Figure 1* shows an operator using a powered machine;

[0009] *Figure 2* shows components of the powered machine of *Figure 1*

in a separated arrangement;

[0010] *Figure 3* shows different tools suitable for use in combination with different drivers;

5 **[0011]** *Figure 4* shows the action of a tool and driver of a powered machine;

[0012] *Figure 5* shows modelled conditions for a powered tool;

[0013] *Figure 6* shows estimated antinode positions along a powered tool;

10 **[0014]** *Figure 7* shows a first arrangement of vibration damping means for the tool of *Figure 6*;

[0015] *Figure 8* shows a second arrangement of vibration damping means for the tool of *Figure 6*;

[0016] *Figure 9* shows a third arrangement of vibration damping means for the tool of *Figure 6*;

15 **[0017]** *Figure 10* shows equations for calculating a comparison set of estimated antinode positions along a powered tool;

[0018] *Figure 11* is a schematic of laboratory testing equipment for testing vibration of a tool in use;

20 **[0019]** *Figure 12* shows an operator using a powered tool having vibration damping means.

Written Description of the Best Mode for Carrying Out the Invention

25 **[0020]** *Figure 1* shows an operator **101** manually operating a powered machine. Herein, the term “powered machine” is used to refer to a machine comprising a driver and a tool configured to be driven by the driver, in

combination. The term “powered machine” includes hand held, portable or supported machines operating under pneumatic, hydraulic, mechanical, electric mains or battery power, that operatively produce a reciprocating motion to transfer energy to a tool, in combination with a tool. Herein, the term “tool” is used to refer to a tool for a powered machine and the term “powered tool” is used to refer generally to a tool in use.

[0021] Powered machine **102** comprises a driver **103** and a tool **104**. In this example, driver **103** is a pneumatic driver and tool **104** is a digger spade. In using the powered machine **102** to dig ground **105**, the operator **101** grips both hands around the handlebar **106** of the driver **103** whilst directing the tool **104** into the ground **105**. During use, undesirable noise is emitted from the powered machine **102**, and undesirable vibrations are transferred from the powered machine **102** to the operator **101** via the handlebar **106**. The level and nature of the undesirable vibration and noise experienced by the operator varies according to many factors, including the condition of the powered machine, the body mass of the operator and the changing physical relationship between the powered machine and the worked medium during the working of the medium.

[0022] The driver **103** and tool **104** components of powered machine **102** are shown in a separated arrangement in *Figure 2*. It can be seen from this Figure that tool **104** comprises a body **201** having a shaped working end **202** and a striking end **203**. The tool **104** has a tool retaining arrangement **204**, in this example in the form of a tool retaining collar extending around the body **201**.

[0023] At the opposite end of the driver **103** to the handlebar **106** is a tool insertion aperture **205**. To connect the tool **104** with the driver **103**, the striking end **203** of the tool **104** is inserted into the tool insertion aperture **205** of the driver **103**. The driver **103** comprises tool retaining means (not shown) configured to co-operate with the tool retaining arrangement **204** to maintain the tool **104** in position within the driver **103**.

[0024] Drivers are typically designed to allow tools for different purposes to be interchangeably used therewith. Shown in *Figure 3* is an example range of different tools, suitable for use in combination with different drivers. The shown tools are a tarmac ® cutter tool **301**, a moil point tool **302**, a heavy-duty burster tool **303**, a digging chisel tool **304**, a narrow chisel tool **305** and a clay spade tool **306**. Tools **301** and **302** each have the same shape cross-section of body and tool retaining arrangement, tools **303** and **304** each have the same second different shape cross-section of body and tool retaining arrangement, and tools **305** and **306** each have the same third different shape cross-section of body and tool retaining arrangement.

[0025] *Figure 4* is a diagram illustrating action of a powered tool **401** and a driver **402**. During operation, the striking end **403** of the powered tool **401** is driven percussively, causing the powered tool **401** to move up and down and/or to rotate, in the directions indicated generally by double-headed arrows **404** and **405** respectively.

[0026] During use, energy is imparted to the tool **401** from the driver **402**.

Energy imparted from action of the driver **402** translated in the axial direction along the tool **401**, indicated by arrow **404**, is represented at **406** as a longitudinal wave. This energy is transmitted along the tool **401** towards the shaped working end **407** thereof. In operation, with the shaped working end **407** of the tool **401** impacting against a worked medium **408**, the dominant modes of vibration of the tool **401** are flexural; represented at **409** as a transverse wave.

[0027] Although the transport of energy from the driver to the tool of a powered machine is a core function within the powered machine, it is desirable to reduce noise and vibration transmitted from the powered machine to the operator thereof, in order to reduce the risk of noise and vibration induced injury. Thus, it is desirable to reduce the noise and vibration effects from energy reflected back from the shaped working end **407** of the powered tool **401**.

[0028] The present invention relates to a technique for reducing undesirable noise and vibration transmitted from a powered machine. A method for providing a tool having vibration damping is provided. Herein, the term "vibration damping" is used to refer to vibration and noise damping. The present invention utilises an approach focussing on undesirable noise and vibration emanating from the tool component, rather than the driver component, of a powered machine.

[0029] In a powered machine, the tool is a medium for the transfer of energy from the driver. Energy is transported in mechanical wave form; the tool itself does not create or dissipate energy. However, energy can be

dissipated from a wave through the boundary between the tool and the immediate environment. For example, noise emanating from a powered tool is caused by decaying oscillations within the tool. Thus, an increase in oscillation decay translates to a reduction in noise.

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[0030] It is known that large amplitude waves occur at resonant frequencies and that the amount of energy transported by a harmonic wave is proportional to the amplitude of the wave. Dissipation of energy transported by the wave reduces the amplitude of the wave and changes the shape thereof. It is preferable for a node to occur near each end of the powered tool.

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[0031] Viscoelastic materials, such as some rubbers and plastics, possess a molecular structure able to store strain energy when deformed and then dissipate the stored energy quickly. Therefore, viscoelastic materials are often used in vibration damping. Since such materials dissipate energy only when distortion occurs, the optimum area in which to position vibration damping means is at an antinode of a wave.

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[0032] However, it is a complex problem to determine where antinodes occur along a powered tool. The present invention provides a model for determining anticipated antinode positions along a tool, when the tool is in use, practically applicable to different shaped tools. From herein, the terms “antinode position” and “node position” are used to refer to an estimated position of an antinode and a node respectively of the vibration of a tool when in use.

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[0033] *Figure 5* shows a tool **501**, having a shaped working end **502** and

a striking end **503**. In this example, the working end **502** of the tool **501** is a narrow chisel.

[0034] The present invention utilises tool modelling. A tool is modelled to have hinged-free boundary conditions; with the tip of the shaped working end modelled as a hinge and the tip of the striking end modelled as a free boundary, free to vibrate. Referring to *Figure 4*, these conditions are derived from the factor of freedom of the striking end of a powered tool when not being impacted by the driver, and an approximation of the shaped working end of the powered tool falling between free and fixed boundary conditions. These boundary conditions are representative of real life working conditions, which vary, for example, with the way a tool is retained in a driver, the depth of a powered tool in a worked medium and the characteristics of the worked medium itself.

[0035] The mode shapes of the first four harmonics for a beam, or rod, having a uniform section and uniformly distributed load under hinged-free boundary conditions are shown at **504**, **505**, **506** and **507** respectively. It can be seen that for each mode shape, there is a node at the hinged end. Shown along each mode shape **504**, **505**, **506**, **507** are coefficients from which each node position occurring along the mode shape can be determined, if the length of the beam is known. Relating this to the tool **501**, the length measurement is taken to be the full length of the tool, i.e. the distance between the tip of the shaped working end **502** and the tip of the striking end **503**.

[0036] To determine antinode positions from each mode shape, first the estimated node positions are determined, by multiplying the relevant

coefficient by the length measurement of the tool. Then the midpoint of the distance between two consecutive node positions along the mode shape is determined and each is taken to be an antinode position for that mode shape.

5 **[0037]** For example, for a tool having a length of 0.8m, there is a first node **508** at the tip of shaped working end and two further node positions, second node position **509** and third node position **510**. The second and third node positions **509**, **510** are determined by multiplying the first node coefficient **511** and the second node coefficient **512** respectively by the length measurement. For this example, second node position **509** occurs at 0.3568m (0.308 x 0.8m) from the first node and third node position **510** occurs at 0.6824m (0.853 x 0.8m) from the first node **508**. To find the two antinode positions, the midpoints between consecutive node positions of the same mode shape are determined. For this example, the first and second estimated antinode positions occur at 0.1784m and 0.5196m from the first node **508** respectively.

20 **[0038]** This antinode position determination process can be simplified with the display of antinode coefficients on the mode shapes shown at **504**, **505**, **506** and **507**, allowing more direct derivation of antinode positions.

25 **[0039]** Figure 6 shows the antinode positions along tool **501** derived from the first three harmonic mode shapes, shown at **504**, **505** and **506** in Figure 5; determined as described with reference to Figure 5. Of the six antinode positions indicated along tool **501**, position **601** is derived from the first harmonic (fundamental frequency) mode shape, positions **602** and **603** are

derived from the second harmonic mode shape and positions **604**, **605** and **606** are derived from the third harmonic mode shape.

[0040] It is found that the energy transported in relation to each harmonic vibration mode successively decreases with each higher harmonic mode. In practice, although it may be useful to find antinode positions along mode shapes for the fourth and higher harmonics, vibration damping of at least one of the first three harmonics offers a greater benefit.

[0041] The determined antinode positions indicate potential optimal positions at which to apply vibration damping means to the tool. In selecting one or more antinode positions, assessment of the practicalities of positioning a vibration damping member at each antinode position is performed. For example, antinode positions **602** and **604** are close to the shaped working end part **502** and antinode position **606** is close to the tool retaining arrangement **607**, leaving antinode positions **601**, **603** and **605** as preferred candidates.

[0042] *Figure 7* illustrates a first vibration damping means for tool **501**. First, second and third vibration damping members **701**, **702**, **703** respectively are each located to cover an antinode; each vibration damping member is individual to an estimated antinode position. As shown, the vibration damping members **701**, **702**, **703** are arranged around the body of the tool **501** with an antinode position **601**, **605**, **603** respectively central thereto.

[0043] A second arrangement of vibration damping means is shown

in *Figure 8*. According to this arrangement, two vibration damping members **801**, **802** are arranged to cover the three antinode positions **601**, **603**, **605**. In this example, damping member **801** is individual to antinode position **603**. Due to the proximity of antinodes **601** and **605**, damping member **802** is conveniently located to cover both antinode positions **601**, **605**. According to this arrangement, damping member **802** is longer than damping member **801** and extends beyond the antinode positions **601**, **605**.

[0044] A third arrangement of vibration damping means is shown in *Figure 9*. According to this arrangement, a single vibration damping member **901** is located to cover the three antinode positions **601**, **603**, **605**. In the shown example, the damping member **901** is long enough to extend beyond the outer antinode positions **601**, **603**.

[0045] As previously described, a model is provided for determining estimated antinode positions along a powered tool. Equation **1001**, shown in *Figure 10*, is a formula for the calculation of the natural frequencies of a beam, or rod, of uniform section and uniformly distributed load. Equation **1002**, also shown in *Figure 10*, is a formula for calculating the wavelength of a wave. In using equation **1001** to calculate the natural frequencies of a tool, simplifications of the shape of the tool are required. However, these formulae **1001**, **1002** can provide a second comparison results set of antinode positions along a tool; this results set is useful for the purpose of comparison with the results from determining antinode positions as described with respect to *Figure 5*.

[0046] Equation **1001** is as follows. Multiply the Young's modulus (E) by the area moment of inertia of beam cross section (I). Divide the result of this multiplication by the mass density of beam material (ρ), by the area of cross section of the beam (S), and by the length of the beam (l) raised to the power of four (4). Take the square root of the result; the result of this is referred to as the first calculation result. Then divide the A coefficient from the relevant harmonic mode shape shown in *Figure 5* or other diagram by two (2) and by pi (~ 3.142). The result of this is referred to as the second calculation result. Then multiply the first calculation result by the second calculation result to find the natural frequency (f_n) for the relevant harmonic.

[0047] The frequency result determined using equation **1001** is useable in equation **1002** to find wavelength. Equation **1002** is as follows. Wavelength (λ) equals wave speed (c) divided by frequency (f). To find the antinodes of the wave, divide the wavelength result found from equation **1002** by four (4). This result gives a first antinode position from one node of the wave. Then, multiply the first antinode position result by three (3) to find a second antinode position from the same node.

[0048] In order to determine the effects of vibration damping on the vibration and noise emissions from a powered tool, it is useful to perform comparative vibration testing of a powered tool having vibration damping means and a similar powered tool not having any vibration damping. A schematic of apparatus **1101** for testing in a laboratory the effects of vibration damping means applied to a powered tool as described above is shown in *Figure 11*. The apparatus **1101** is arranged to allow simulation of modelled boundary conditions for the tool being tested. Each tool, for

example tool **1102**, is tested according to a vibration magnitude method, in which the striking end of the tool is impacted and readings are taken from an accelerometer **1103** mounted on the body thereof, with readings being taken from different positions along the tool.

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[0049] *Figure 12* shows an operator **1201** manually operating a powered machine **1202**, comprising a driver **1203** and a tool **1204** having vibration damping means located to cover an estimated antinode position determined as described with reference to *Figure 5*. In this example, the vibration damping means comprises a single vibration damping member **1205**. In the shown example, driver **1203** is a pneumatic driver and tool **1204** is a digger spade, suitable for working ground **1206**. The operator **1201** is gripping the handlebar **1207** of the driver **1203** with both hands whilst directing the tool **1204** into the ground **1206**. The vibration damping member **1205** functions to reduce vibrations transferred from the powered machine **1202** to the operator **1201**. This function makes the powered machine more comfortable for the operator to use, and reduces potentially injurious vibrations and noise.

[0050] Preferably, the vibration damping means is fabricated from a different material to that of the tool. In this example, the tool **1204** is a forged and machined steel tool of length 0.62m, and the vibration damping member **1205** is a polypropylene moulded tube of length 0.03m and thickness 0.002m. For a tool of approximately this length, practical vibration damping member dimensions are in the approximate range of between 0.02m and 0.04m in length and between 0.001m and 0.003m in thickness.

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[0051] A vibration damping member may be fitted to a tool by one of various methods, for example by an adhering method or method in which a vibration damping member is mechanically forced onto the tool. Particularly applicable for vibration damping members in the form of a collar is a shrinking method during which the diameter of the vibration damping member is shrunk from a diameter initially greater than that of the body of the tool until contact between the vibration damping member and the tool is made. For effective damping, there should be good contact between a vibration damping member and the tool on which it is located. If the selected material is not self-adhering to a tool, adhesive, such as epoxy, may be used between the vibration damping member and the tool. Preferably, a vibration damping member is fabricated from a material composition having a high resistance to abrasion, to reduce the wear thereof. A vibration damping member may have internal and/or external protrusions to account for different shapes of tool body.

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[0052] The described method of providing a tool for a powered machine having vibration damping is applicable to tools of various designs and sizes; for example, tools made by different processes, including forging and/or machining, tools having different shaped working ends, tools having different cross-section body shapes and/or different material composition. It is to be understood, however, that the described method of providing a tool with vibration damping means involves tool modelling, and the correlation between the results found by this method compared to the real life case is variable according to the specification of individual tools and the usage thereof.

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